

In the specification:

Please amend the paragraph bridging pages 10 and 11 as follows:

The work robot 11 is displaceable along the carriage guide in one or several so-called work regions 17-20. In the simplest case, the work regions 17-20 are formed by workpiece surfaces to be processed, while the processing head 10 of the work robot 1 in these work regions 17-20 for example produces openings in the workpiece surfaces. For forming the openings at desired locations in the corresponding working regions 17-20 by the work unit 15 formed as a drill, these desired positions are stored as coordinates K of the work regions 17-20 in the computing and control unit 14. The coordinates K are identified on a coordinate system 21 which moves together and determines the corresponding work regions 17-20. Furthermore, the work robot 1 can move by the carriage guide 3013 in a calibration region 22 which can be formed by a caliber plate 23. So called reference coordinates RK related to a stationary global coordinate system 24 are associated with the calibration region 22 and also can be stored in the computation and control unit 14.

Please amend the paragraph bridging pages 13 and 14 as follows:

In accordance with the shown embodiment of the invention, the calibration region 22 and the work regions 17-20 occupy the same or similar position in space, wherein this same position in accordance with the present position is limited to the inclination of the calibration region 22 and the work regions 17-20 in horizontal and vertical directions. It is thereby guaranteed that the processing device 2 and the processing head 10 associated with it assume during running through the working regions 17-20 and also during running the calibration region 22 the same work poses 26. For protecting the calibration region 22 from the disturbing environmental influences such as for example vibrations, temperature fluctuations, and dirtying, the calibration region 22, in deviation from the shown arrangement, can be displaced in vertical or horizontal directions relative to the work regions 17-20 but arranged approximately on the same inclination in horizontal and vertical directions. For designing the position of the work regions 17-20 flexible, the coordinates K of the work regions 17-20, as mentioned above, are defined in a co-moving coordinate system 21, while the reference coordinates RK of the stationary calibration region 22 are defined in a stationary so-called global coordinate system 24.

Please amend the paragraph bridging pages 16 and 17 as follows:

In accordance with a further embodiment of the present invention, the caliber plate 2223 is displaceable in horizontal and vertical directions without an inclination change. Therefore on the one hand it is usable on different processing devices 1, 2 and in addition can be utilized in a favorable outside conditions on the same processing device 1, 2 for example in a protected position. For providing the possibility of adapting the caliber plate 23 further to differently positioned work regions 17-20, the caliber plate 23 can be changed in its inclination in correspondence with directions of arrows 31, 32. The inclination change is performed so that the new work regions 17-20 and the new calibration region 22 have again the same inclination, so that the processing device 2 and the processing head 10 associated with it assume approximately the same work poses 26m both during running over the work regions 17-20 and during running over the calibration region 22.

Page 17, amend the paragraph in lines 4-12 as follows:

The reference points 2229 in the simplest case can be provided as openings 34 or socket pins 35. Thereby the sensor 33, which is connected with the computation and control unit 33 and arranged in the processing head 10 of the processing device 2, can scan the reference points 29 in a simple manner. The reference points 2229 can be also formed by reflecting points 36 on the caliber plate 23 to keep the expenses for providing the reference points 29 and the caliber plate 23 as low as possible. The reflecting points 36 can be detected for example by an optical sensor 33.